

In the Claims:

Please amend the claims as follows:

1-10 (cancelled)

11. (cancelled)

12. (previously amended) The manipulator according to claim 34, further comprising:
a first attachment operatively connected to the rear arm part and operative to receive the
cabling.

13. (previously amended) The manipulator according to claim 34, further comprising:
a second attachment operatively connected to the auxiliary arm and operative to receive
the cabling.

14. (previously presented) The manipulator according to claim 12, wherein a first
attachment is arranged at a distal end of the supporting arm.

15. (previously presented) The manipulator according to claim 12, wherein the first
attachment surrounds the cable.

16. (previously presented) The manipulator according to claim 13, wherein the second

attachment surrounds the cable.

17. (previously amended) The manipulator according to claim 34, wherein the supporting device winds the cabling around the front arm part when the second arm is rotated.

18. (previously amended) The manipulator according to claim 34, wherein the first axis and the rotation axis are perpendicular to each other.

19. (currently amended) The manipulator according to claim 34, further comprising:
a spiral spring operative to rotate the supporting arm about the ~~second~~ rotation axis to apply the spring force to the cabling.

20. (previously presented) The manipulator according to claim 19, further comprising:
a casing operative to protect the spring.

21. (previously presented) The industrial robot according to claim 20, wherein the casing is a tensioning element operative to tension the spring.

22. (previously amended) The manipulator according to claim 34, wherein the supporting arm is connected in the vicinity of a proximal end of the rear arm part of the first arm.

23. (previously amended) The manipulator according to claim 34, further comprising:
a rigid tube arranged between the supporting arm and the auxiliary arm and enclosing the

cabling.

24. (previously presented) The industrial robot according to claim 23, wherein the tube is bendable.

25. (previously amended) The manipulator according to claim 34, further comprising: snap-in cable attachments provided on the supporting arm and the auxiliary arm.

26. (previously amended) The manipulator according to claim 34, wherein the supporting arm comprises an angle part operative to permit the cabling to be supported centrally over the first arm.

27. (currently amended) The manipulator according to claim 34, wherein the supporting arm applies the spring pulling force in a longitudinal direction of the cabling and lifts the cabling away from the first arm.

28. (previously amended) The manipulator according to claim 34, wherein upon rotation of the front arm part about the first axis the cabling is wound around the front arm part.

29. (previously amended) The manipulator according to claim 34, wherein the supporting arm comprises a plurality of arms arranged in a four-linkage system.

30. (previously amended) The manipulator according to claim 34, further comprising:

a spring arrangement operative to apply a spring force to the supporting arm.

31. (previously presented) The industrial robot according to claim 30, wherein the spring arrangement comprises a torsion spring, a tensile spring, or a compression spring.

32. (cancelled)

33. (cancelled)

34. (currently amended) An industrial robot manipulator, comprising:

a first arm comprising a front arm part and coaxial a rear arm part, the front arm part being journaled in the rear arm part such that the front arm part is rotatable about a first axis relative to the rear arm part;

a second arm rotatably connected to the front arm part of the first arm and rotatable about a second axis;

cabling extending along the front arm part and the rear arm part; and

a supporting device operative to support the cabling, the supporting device comprising

a supporting arm connected to the rear arm part and rotatably supported about a rotation axis, the supporting arm ~~part~~ being rotatable about the rotation axis between a relaxed position and an extended position and applying a spring pulling force to the cabling ~~along a longitudinal direction of~~ to guide and hold the cabling stretched between the supporting arm and the second arm, and

an auxiliary arm operatively connected to the ~~front~~ second arm part.